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ANDROID HUMANOID ROBOT - (HRP-4C)

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ABSTRACT

This paper presents an overview of our work towards Android Humanoid Robots specifically HRP-4C that can work alongside people as cooperative teammates in dancing demos. We present our theoretical framework based on a novel constructional components necessary for the real movement task to respond to the human speech on the basis of speech recognition and demonstrate its use to allow a human to work cooperatively as a dancing team for various dance performances. Such issues must be addressed to enable many new and exciting applications for humanoid robots that require them assist ordinary people in daily activities or to work as capable members of human-robot teams.

KEYWORDS

Android, Humanoid Robots , HRP-4C, Speech recognition, Movements of human.

INTRODUCTION

HRP-4C^[3] is a female humanoid robot^[2], created by the National Institute of Advanced Industrial Science and Technology -a Japanese research facility. It can move like a human and responds based on speech recognition^[4]. It is capable of recognizing ambient sounds and, by using the vocal synthesizer ,Vocalic, can sing.The HRP-4C^[3] has a realistic head, and the average figure of a young Japanese female. Recent upgrades have allowed HRP-4C^[3] to mimic human facial and head movements, as well as execute dance steps, resulting in the most realistic performance yet.

CONSTRUCTIONAL TECHNOLOGIES

HRP-4C^[3] was efficiently developed based on the User Centered Robot Open Architecture utilizing the fundamental Robot Technologies (RTs) including Real-time Linux, RT middleware, Robot Simulator OpenHRP3, Speech Recognition^[4] and Bipedal walking technology. HRP-4C^[3] is expected to be useful in the entertainment industry, for device evaluation for humans working as human simulators, and mechanical products to assist human movements by incorporating the following new functions and features:

FIGURE 1

1. Looks like a human being with a height of 158 cm and body weight of 43 kg (including the battery), and the positions of the joints and dimensions are set to the average values for young Japanese females in the "Japanese Body Dimension Database 1997 – 98."
2. To closely mimic the movements of humans, there are 3 degrees of freedom in the hip, 3 in the neck and 8 in the face.
3. By adopting the walking control technology developed in HRP and motion-captured human movements for reference, the robot walks and moves very much like a human being.
4. The speech recognition^[4] component of RT middleware, which is installed in the computer in the head section, recognizes human speech and the robot can respond in various ways.

Furthermore, HRP-4C^[3] inherits the technologies of HRP-2 and utilizes patented technology of Honda Motor Co. Ltd.

DESIGN OF APPEARANCE

The complete set of appearance with design constraints can be discussed as:

Head Joints

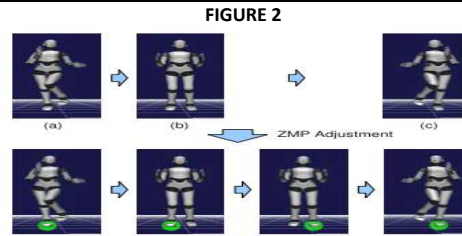
HRP-4C^[3] has 8 actuators in its head and accordingly can make facial expressions. To realize a head size close to the average young female , there is need to limit the number of degree of freedom(DOF) of the head. Due to this, HRP-4C^[3] can not perform some facial expressions like winking but can show smile , surprise , anger etc.

Hand Joints

The designing of hands of HRP-4C^[3] to create motion in dance performance is again limited to minimum DOF. The four fingers from the index to the little fingers are driven by one servomotor and the thumb is driven by another.

Towards Human like Walking and Motion

A couple of algorithms have been developed to generate human-like motion and walking from mocap data. The robot has been associated with a special software tool having control mechanism to stabilize a humanoid robot motion. It can be used to quickly create the motion through an interactive user interface. The software is based on the computation concept named **Zero Moment Point (ZMP)** to detect poses that are unstable.



User can freely design the key poses. If a pose is not stable, the software automatically detects that the pose is a problem and modifies it. And if user doesn't like the "corrected" pose then, can choose another pose and keep trying until satisfied with the movements. Thus, software automatically adds a key pose needed to maintain stability.

Interaction using Speech Recognition

In the technology of HRP-4C^[3], an open source speech recognition^[4] engine named **Julian** is used. It runs on the CPU embedded on the head of it. To realize robust recognition against ambient noise, an operator uses wireless Bluetooth microphone to send voice commands. The recognition result is transmitted to motion control software running on other CPU in the body of HRP-4C via RT Middleware. In the given figure, the operator is speaking voice command – "Look Surprised" and accordingly HRP-4C^[3] demonstrated the surprise motion.

CONCLUSION AND FUTURE WORK

In this paper, there is an overview about android humanoid robot HRP-4C^[3]. The robot has the appearance and shape of a real human being, specially, an average young Japanese female. It can perform biped walk using its own battery and can interact with humans using speech recognition^[4]. It is expected to be used in the entertainment industry such as for exhibitions and fashion shows. Since its appearance and shape are human-like, it can be also used as a human simulator to evaluate devices....

The software of HRP-4C^[3] is still under development for the project, was carried out with a tight schedule. One of the urgent goal is to realize a reliable human-like biped walking with stretched knees.

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